

L Number	Hits	Search Text	DB	Time stamp
1	45	robot same synchronous adj control	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2003/10/22 10:14
2	11	synchronism same soft adj start	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2003/10/22 10:59
3	2	motion adj start same synchronism adj start	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2003/10/22 11:04
4	1	motion adj synchron\$8 adj start	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2003/10/22 11:26
5	11	simultaneous adj position adj control	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2003/10/22 11:28
6	6	synchronous adj numerical adj control	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2003/10/22 11:32
7	11	position adj control same follower adj element	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2003/10/22 11:35
8	0	synchron\$8 with acclerat\$4 adj control	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2003/10/22 11:36
9	216749	master ajd element with acclerat\$4 adj control	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2003/10/22 11:36
10	0	master adj element with acclerat\$4 adj control	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2003/10/22 11:36
11	3	acclerat\$4 adj control	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2003/10/22 11:36
12	123	synchron\$8 with accelerat\$4 adj control	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2003/10/22 12:11
13	1177	(movement or motion) near2 (tracking or tandem) same control	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2003/10/22 12:13
14	3	(movement or motion) near2 (tracking or tandem) same control same (velocity and acceleration)	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB	2003/10/22 12:16

15	111	position adj tracking adj control	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM TDB	2003/10/22 12:16
16	0	position adj tracking adj control with (acceleration and velocity)	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM TDB	2003/10/22 12:16
17	0	position adj tracking with control with (acceleration and velocity)	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM TDB	2003/10/22 12:17
18	15	position adj tracking with control with (acceleration or velocity)	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM TDB	2003/10/22 12:19
19	3304	positional adj relationship same control	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM TDB	2003/10/22 12:19
20	16	maintaining adj positional adj relationship same control	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM TDB	2003/10/22 12:22
21	0	periodic adj motion same soft adj start	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM TDB	2003/10/22 12:23
22	0	(tandem or tracking) adj periodic adj motion same control	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM TDB	2003/10/22 12:24
23	0	(tandem or tracking) adj periodic adj motion	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM TDB	2003/10/22 12:24
24	23	(tandem or tracking) same periodic adj motion	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM TDB	2003/10/22 12:28
25	0	relative adj motion adj control same (accleration and velocity)	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM TDB	2003/10/22 12:28
26	71	relative adj motion adj control	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM TDB	2003/10/22 12:37
27	4	setting adj start adj position same synchron\$7	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM TDB	2003/10/22 12:38
28	91	velocity near2 linearly same control	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM TDB	2003/10/22 12:39